**TEAM 2 - WEEK 6 REPORT - MARCH 6th - 408i SPRING 2022**

**Michael Delatte**

This week Michael converted all his code into python code. This will allow him to use the libraries available in python. With this, he will soon attempt to make models based on current decisions with weights based on past systems. My goal is to be able to do any corner to any corner solutions, but he will start with fixed start and endpoints to provide a solid proof of concept.

**Wesley Catbagan**

In the lab this week Wesley attempted to change his approach to the map. After weeks of working with the motors to track the robot in the map, he figured a different approach might be necessary. He tried testing the IMU to get a sense of direction to work within the map. So far he has something working with the new approach, but will need more time to work everything out. In lab this week he will spend the majority of his time on this.

**Erik Bryson**

This week Erik got the robot to follow the white lines near perfectly, and even deals with curved lines! This was a massive improvement, as all that need adjustment now is intersection recognition. Once it can properly read T,+,L, and end intersections, we have everything from the physical systems to properly complete this project.